

SYSTEM AND METHOD FOR RADAR-ASSISTED CATHETER  
GUIDANCE AND CONTROL

Yehoshua Shachar

Appl. No.: Unknown

Atty Docket: MNETEC.003A

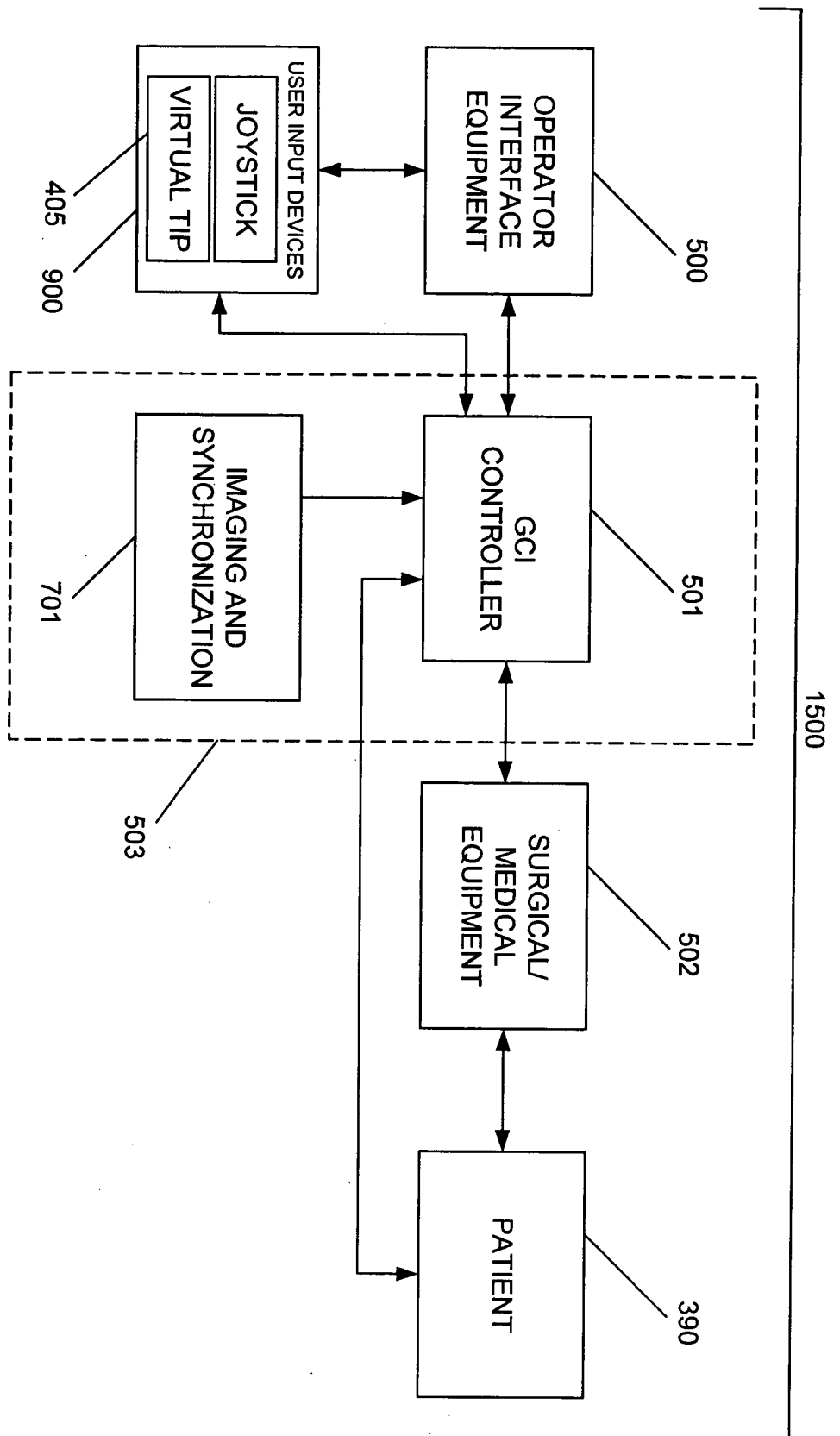


FIG. 1

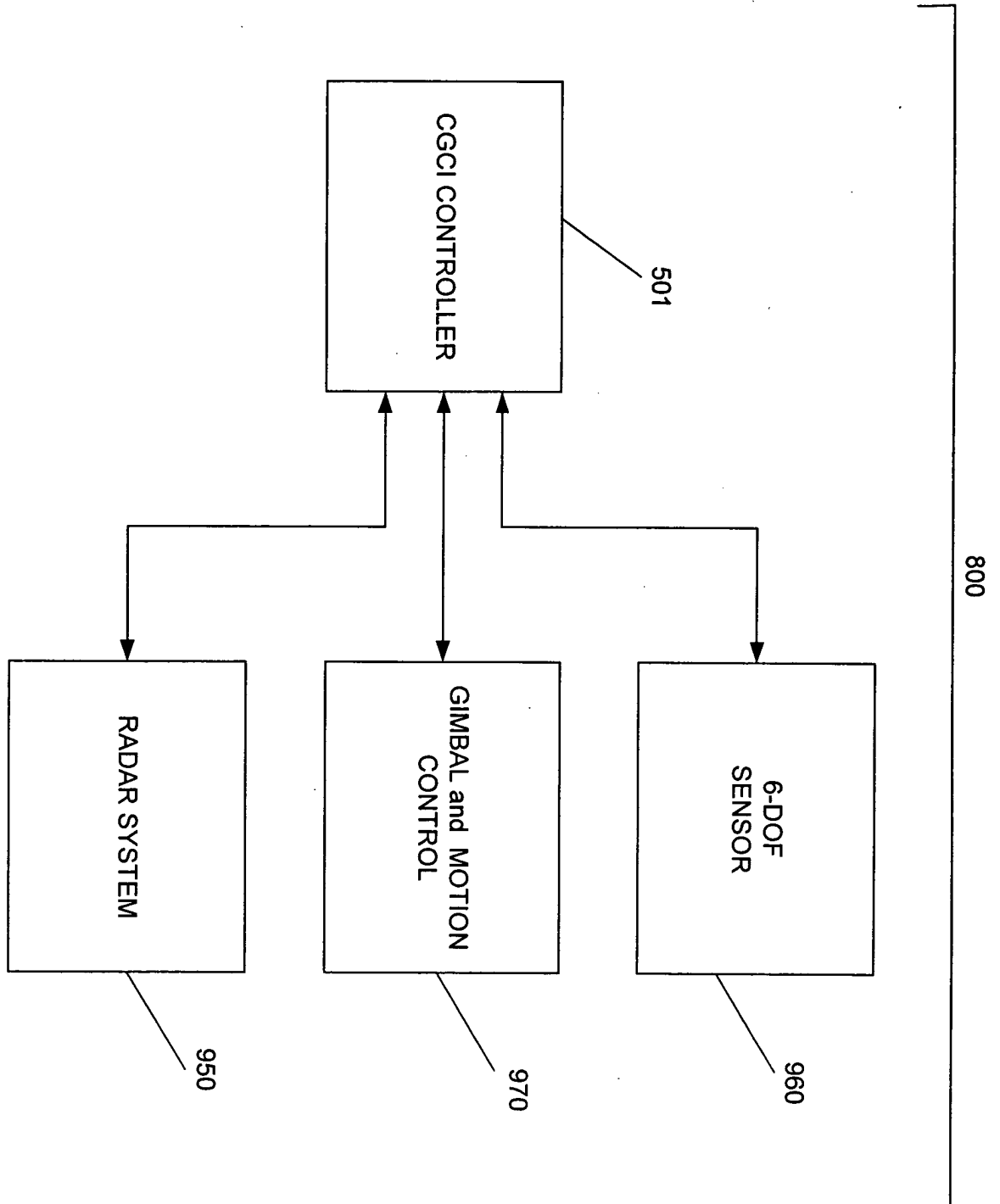


FIG. 1A

FIG. 2

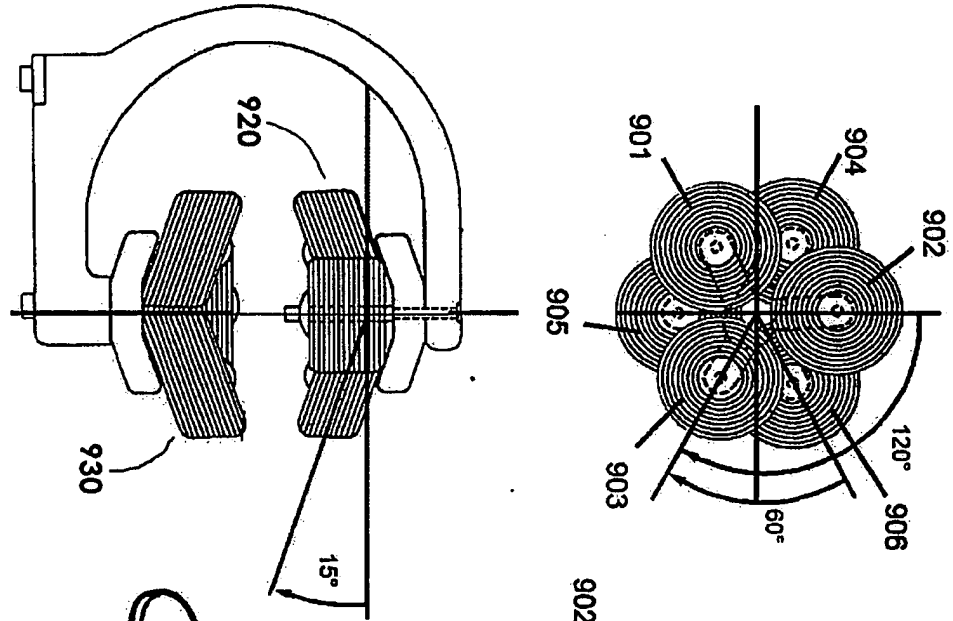
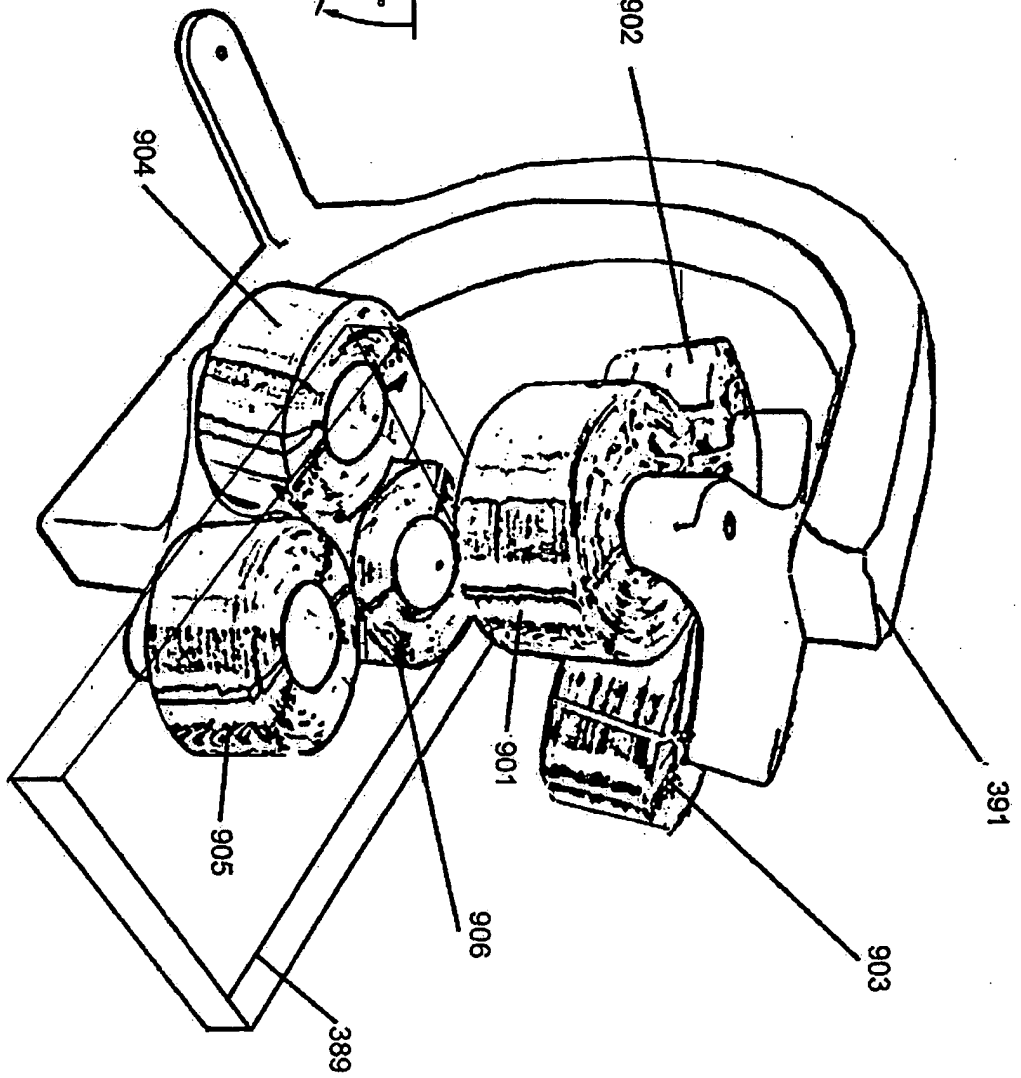


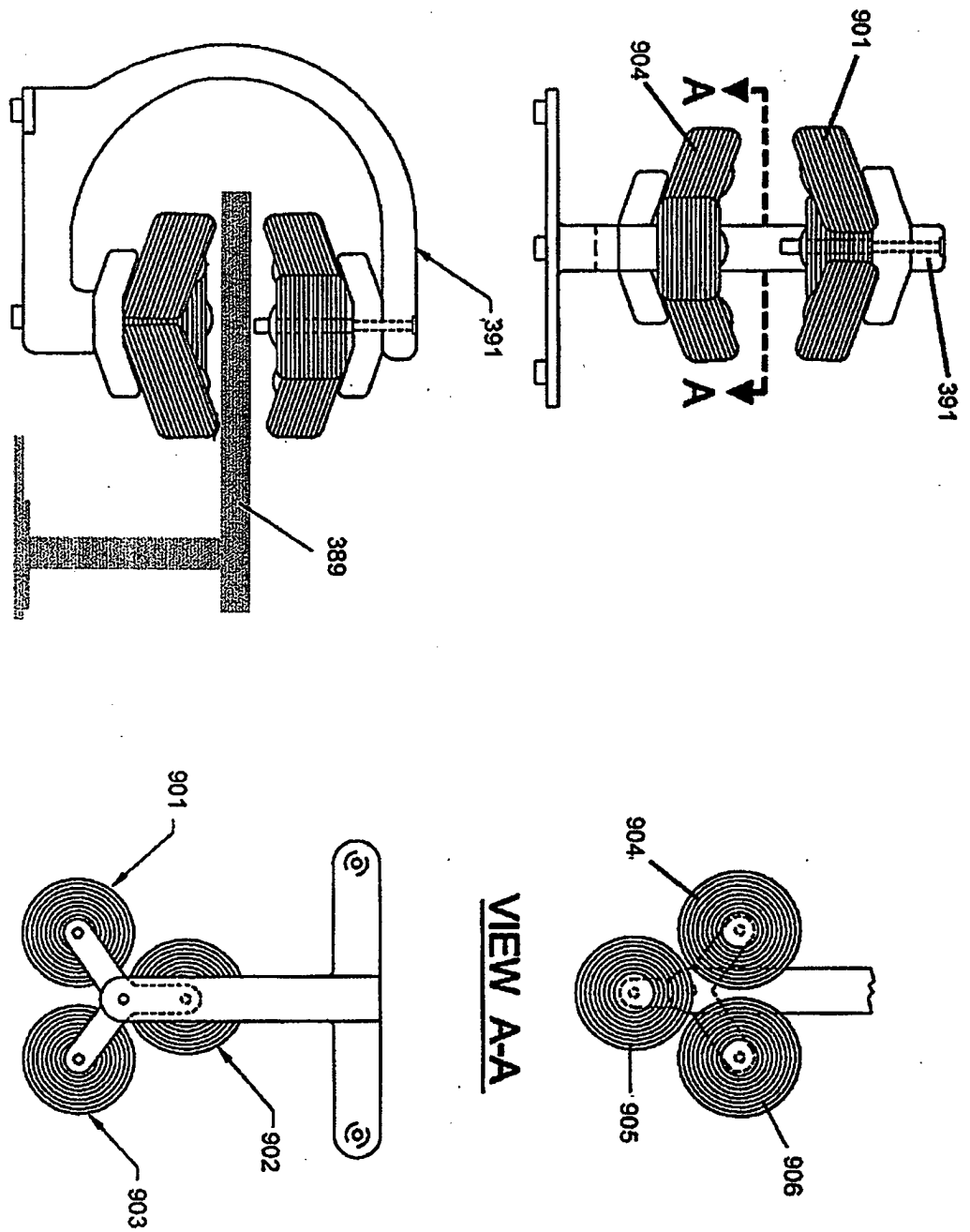
FIG. 2A



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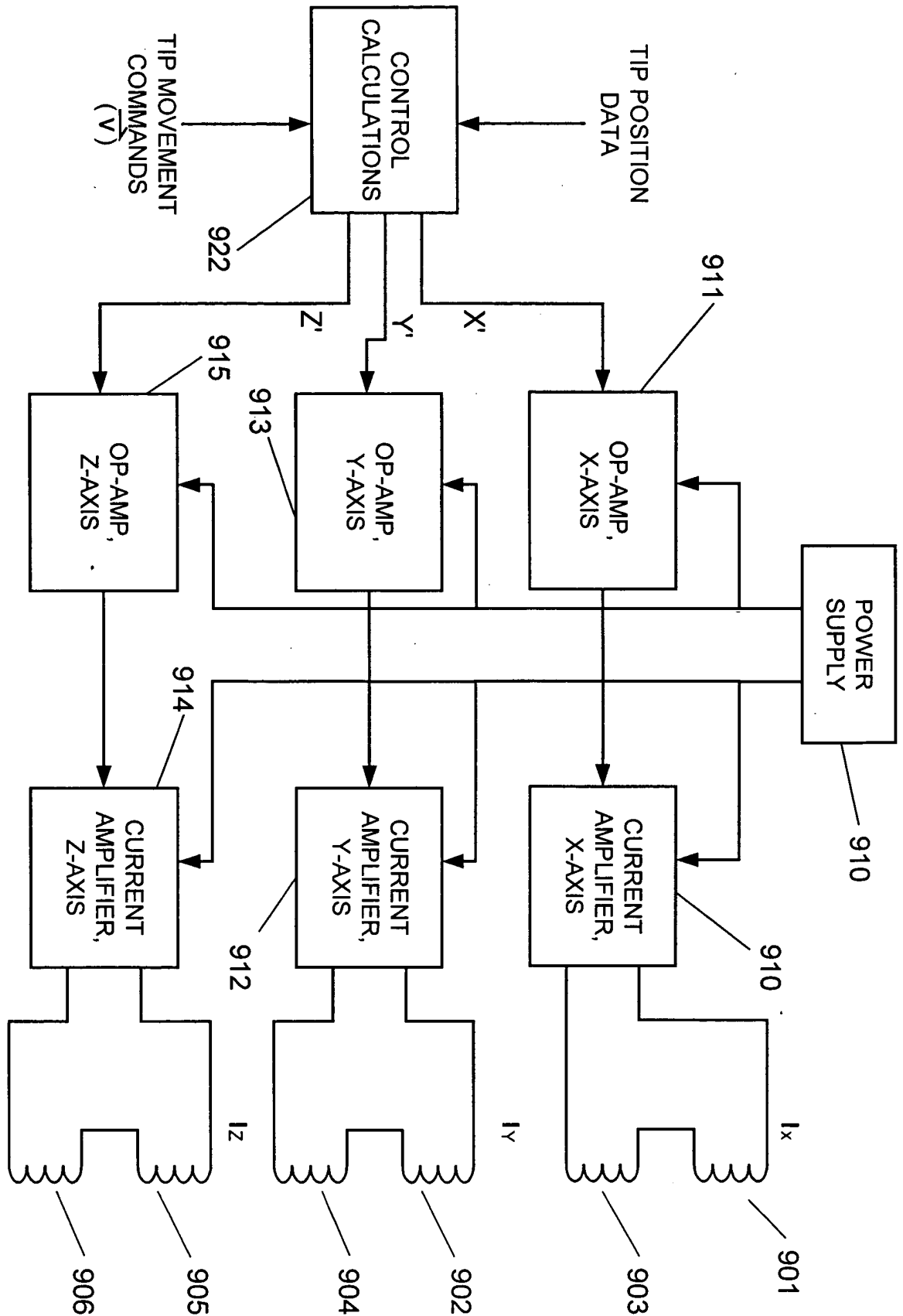


Fig. 2C

$$\begin{bmatrix} B_x \\ B_y \\ B_z \end{bmatrix} = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} v_{ix} \\ v_{iy} \\ v_{iz} \end{bmatrix}$$

921 922 923

FIG. 2D

$$\begin{bmatrix} B_x \\ B_y \\ B_z \end{bmatrix} = \begin{bmatrix} C_{11} & C_{12} & C_{13} \\ C_{21} & C_{22} & C_{23} \\ C_{31} & C_{32} & C_{33} \end{bmatrix} \begin{bmatrix} l_1 \\ l_2 \\ l_3 \end{bmatrix}$$

921 925 926

FIG. 2E

$$\begin{bmatrix} B_x \\ B_y \\ B_z \end{bmatrix} = \begin{bmatrix} R_{11} & R_{12} & R_{13} \\ R_{21} & R_{22} & R_{23} \\ R_{31} & R_{32} & R_{33} \end{bmatrix} \begin{bmatrix} l_1 \\ l_2 \\ l_3 \end{bmatrix}$$

921 927 926

FIG. 2F

$$\begin{bmatrix} B_x \\ B_y \\ B_z \end{bmatrix} = \begin{bmatrix} R_{11} & R_{12} & R_{13} \\ R_{21} & R_{22} & R_{23} \\ R_{31} & R_{32} & R_{33} \end{bmatrix} \begin{bmatrix} C_{11} & C_{12} & C_{13} \\ C_{21} & C_{22} & C_{23} \\ C_{31} & C_{32} & C_{33} \end{bmatrix} \begin{bmatrix} v_{ix} \\ v_{iy} \\ v_{iz} \end{bmatrix}$$

921 927 925 923

FIG. 2G

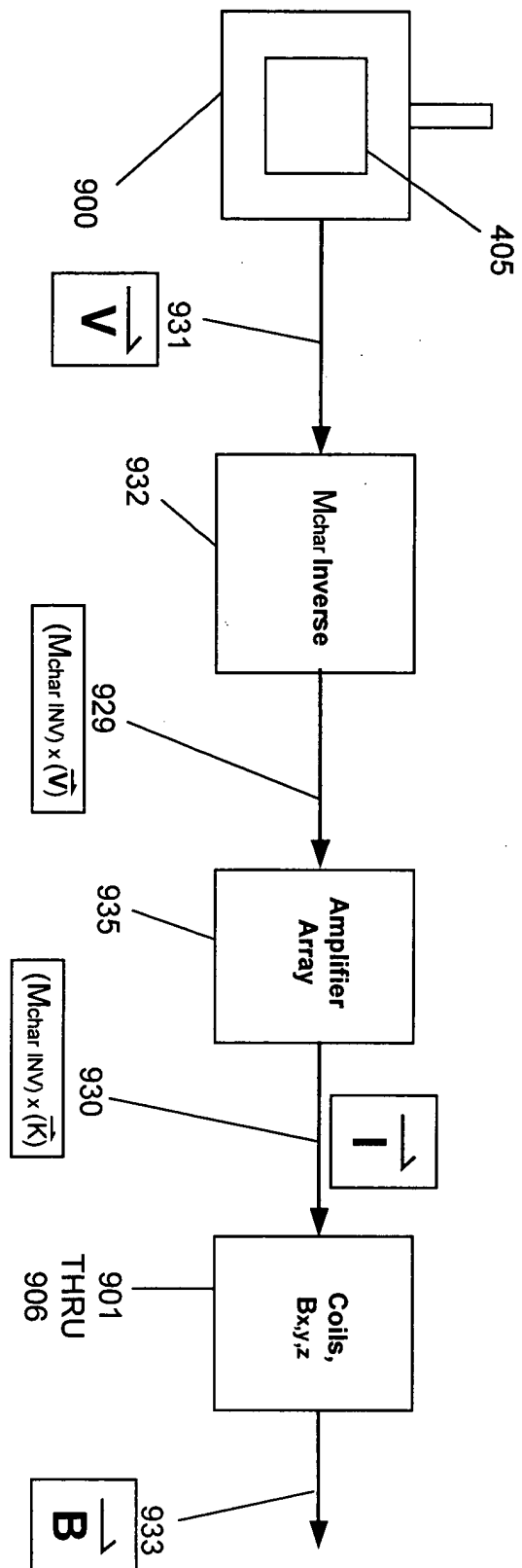


Fig. 2H

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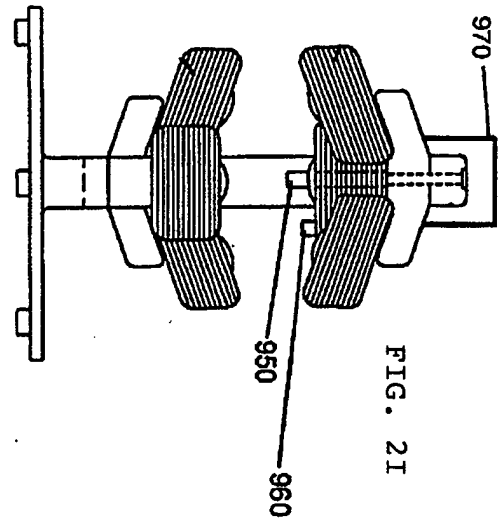


FIG. 2I

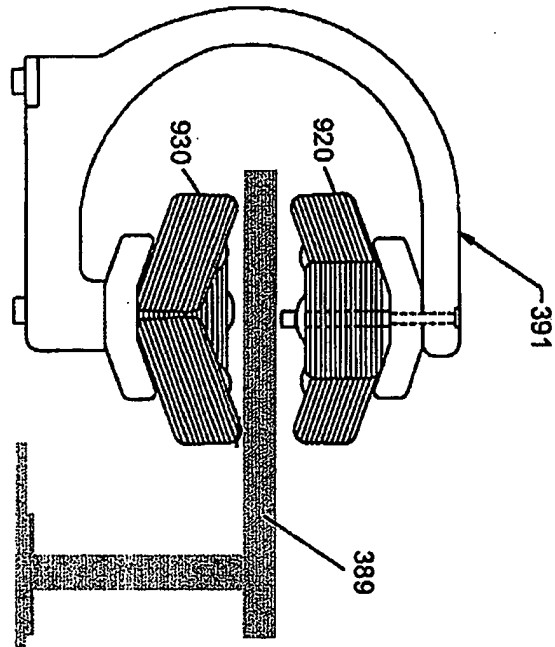


FIG. 2J

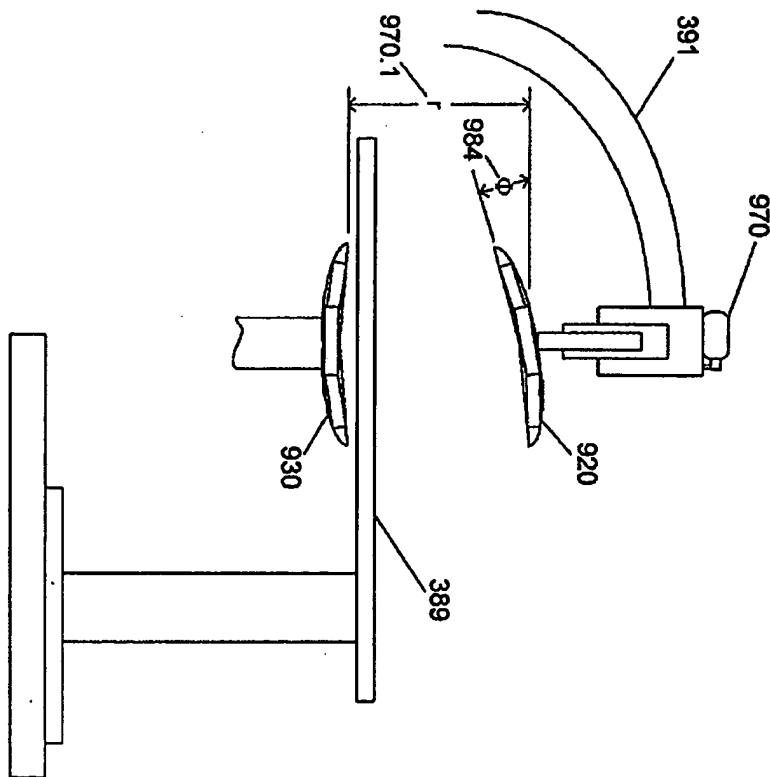
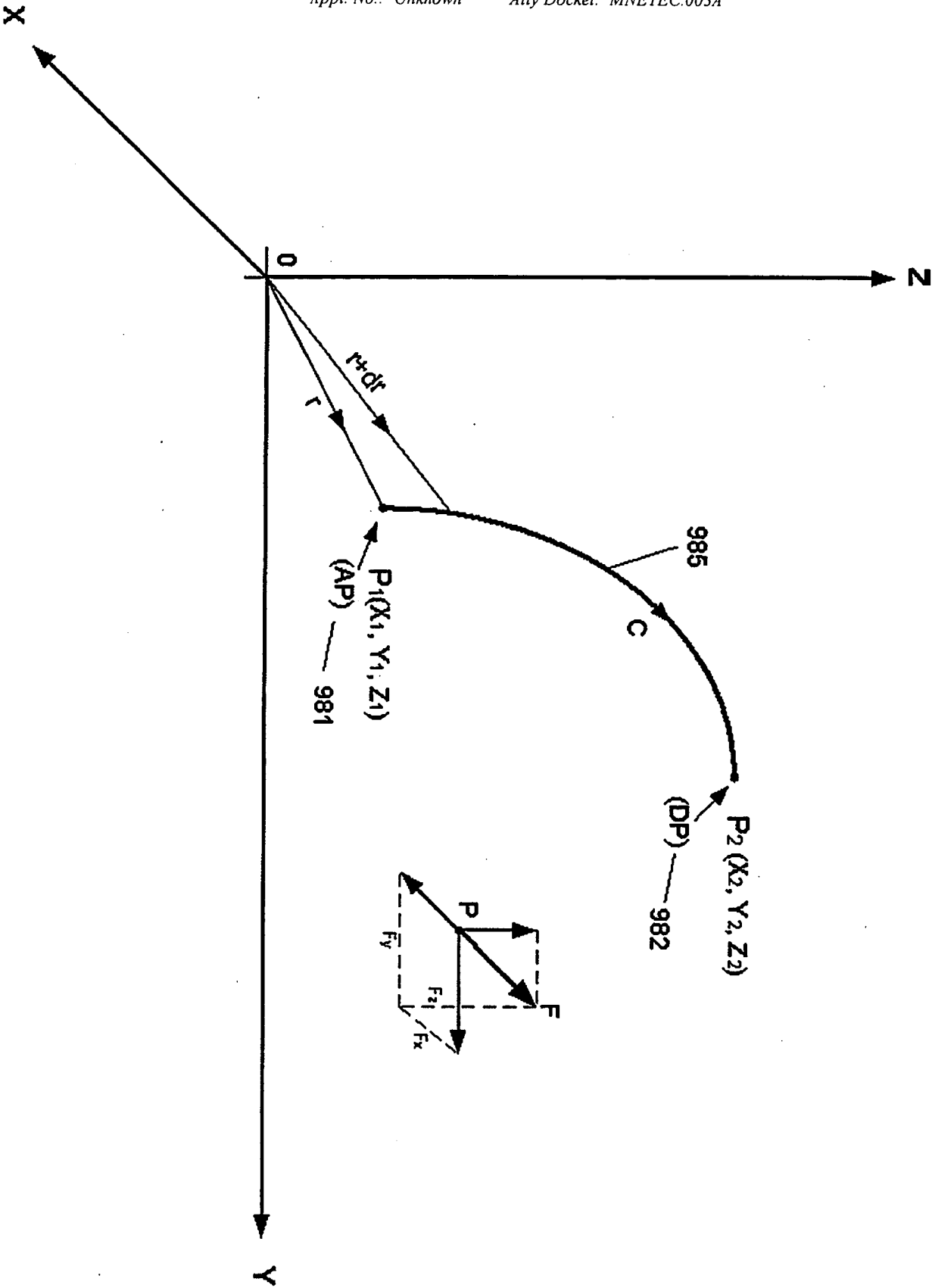
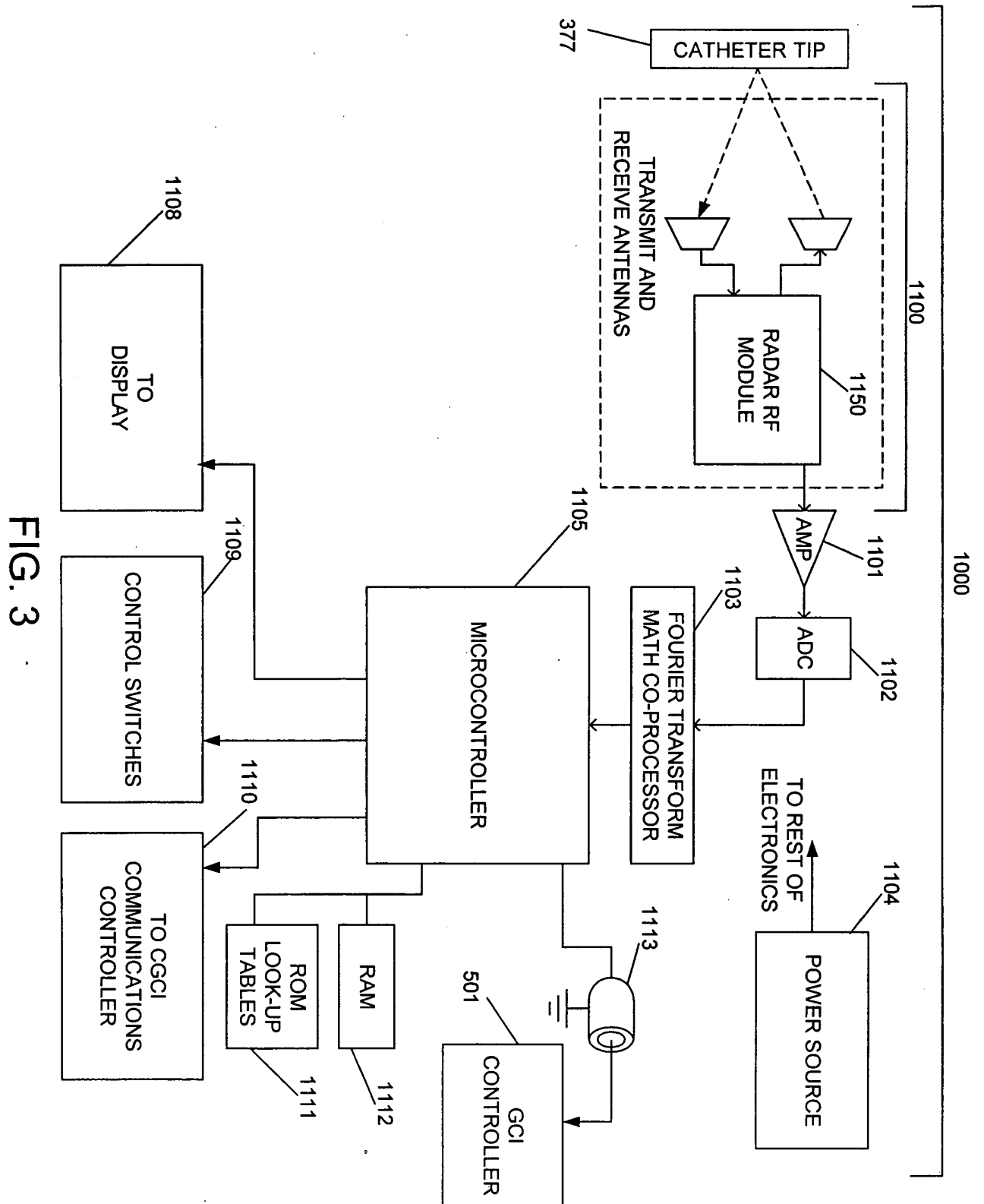


FIG. 2K



FIG. 2L





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Fig. 3A

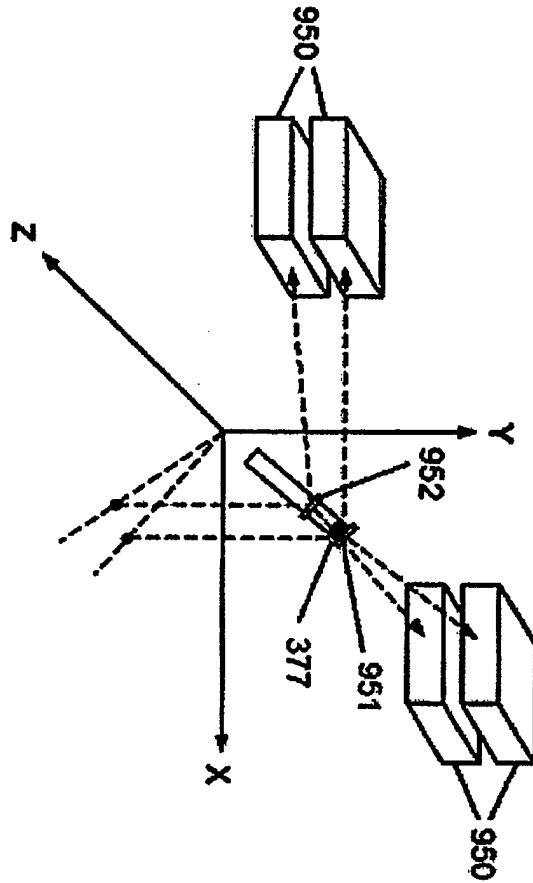
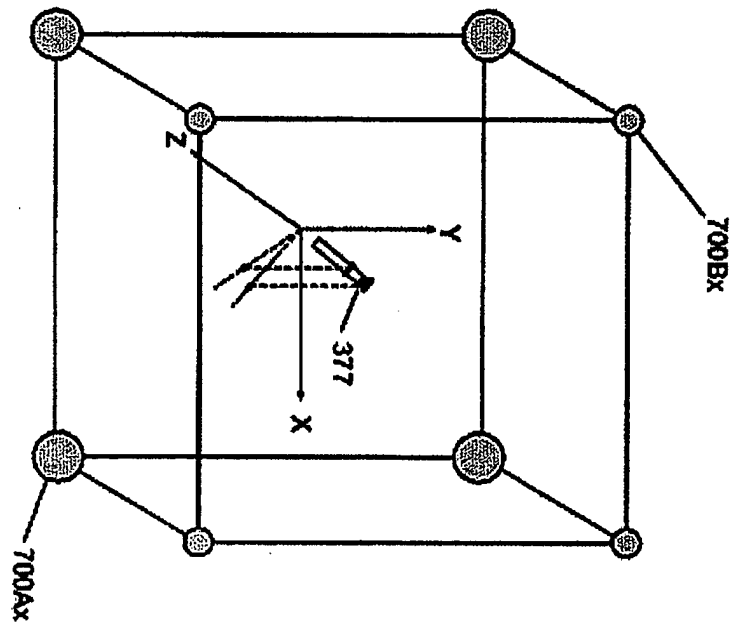


Fig. 3B



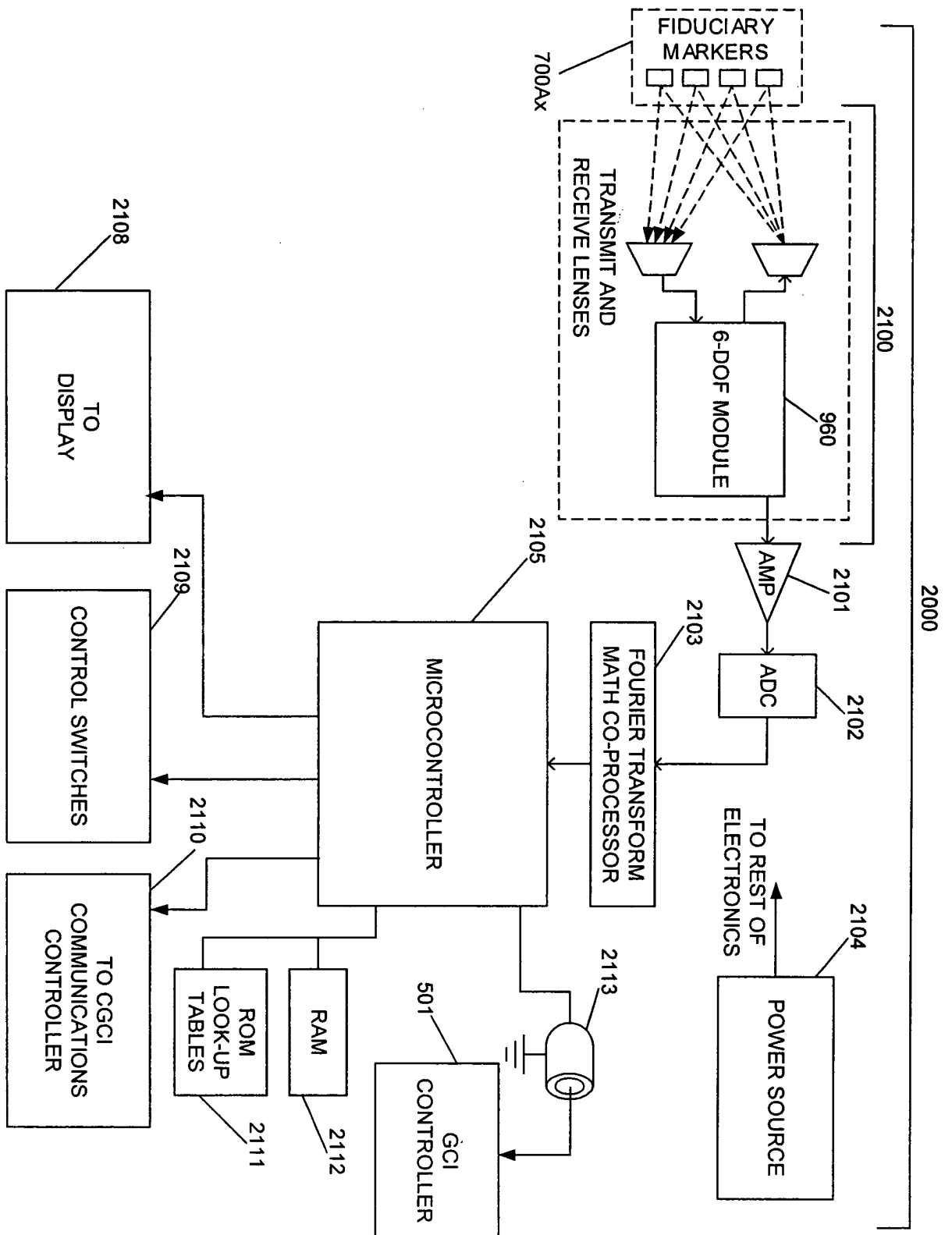


FIG. 4

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FIG. 5

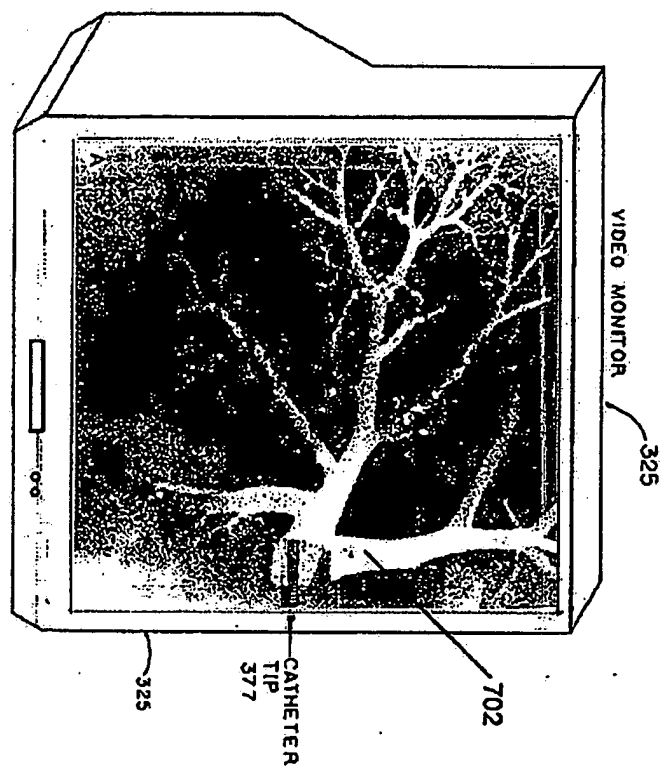
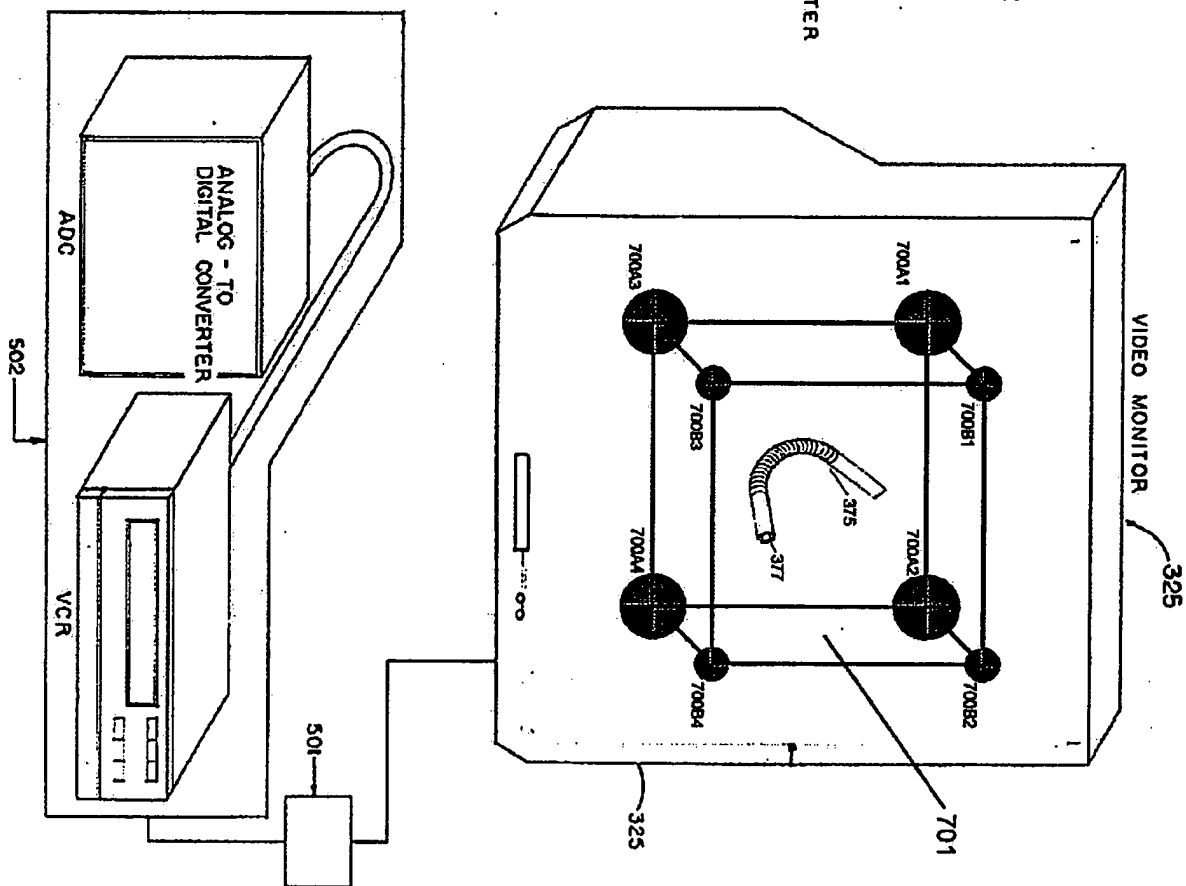


FIG. 5A



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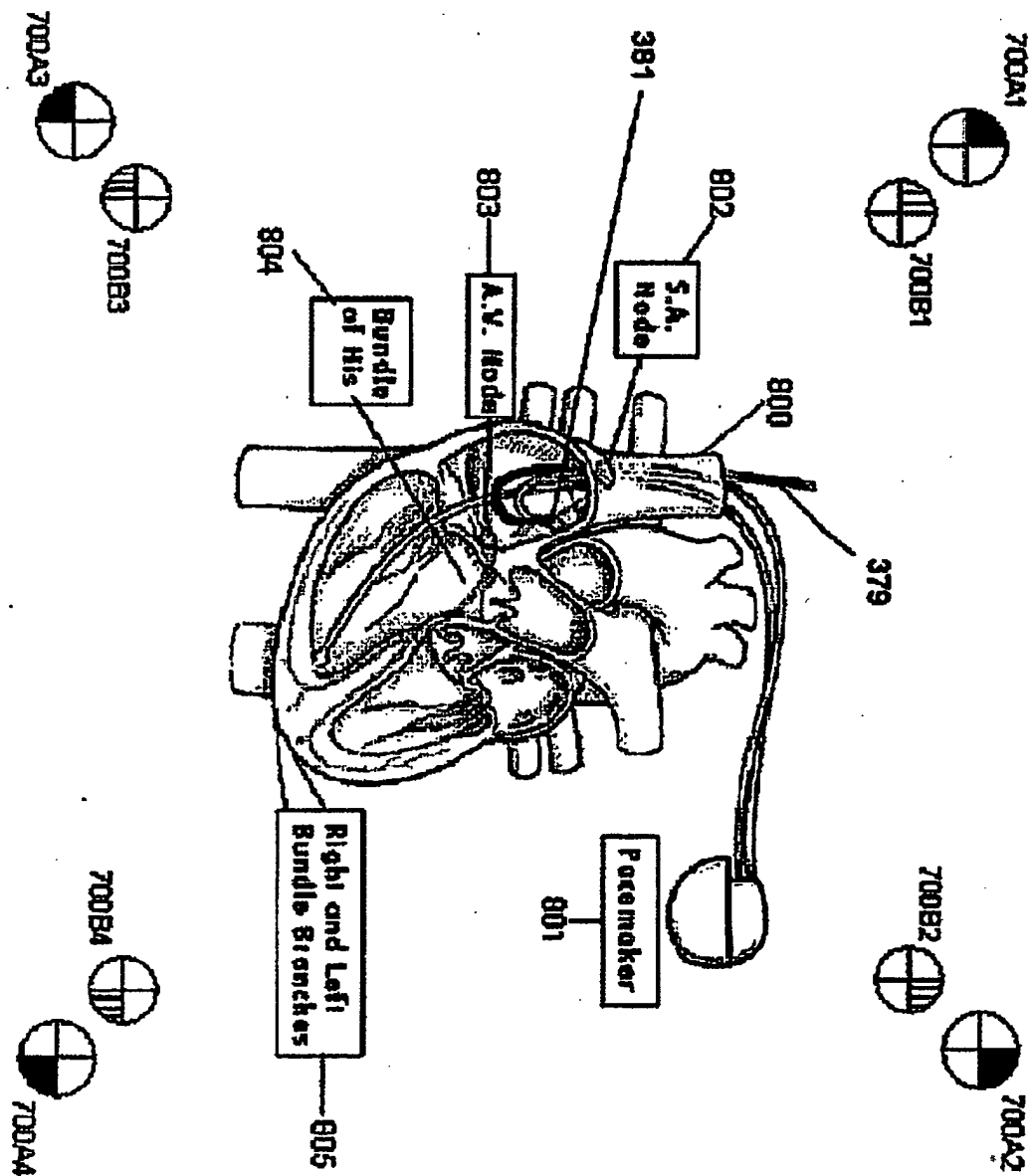


FIG. 5B

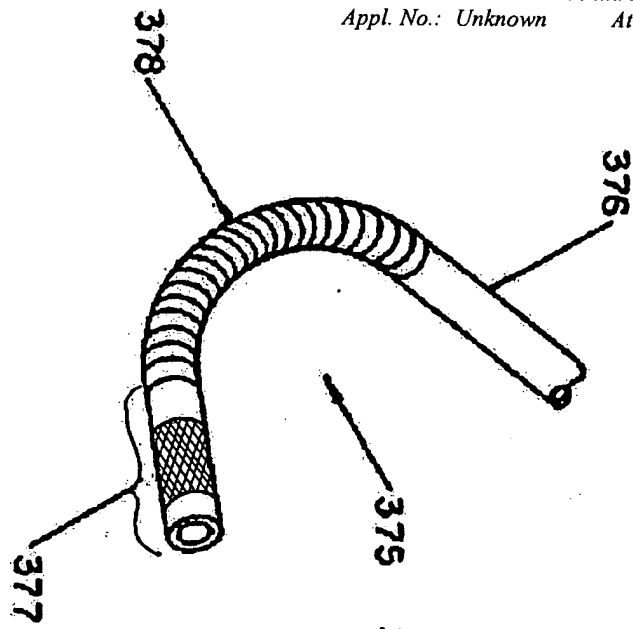


FIG. 6

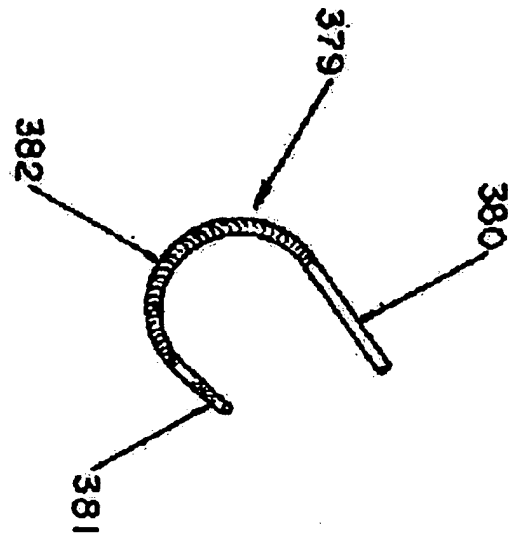


FIG. 6A

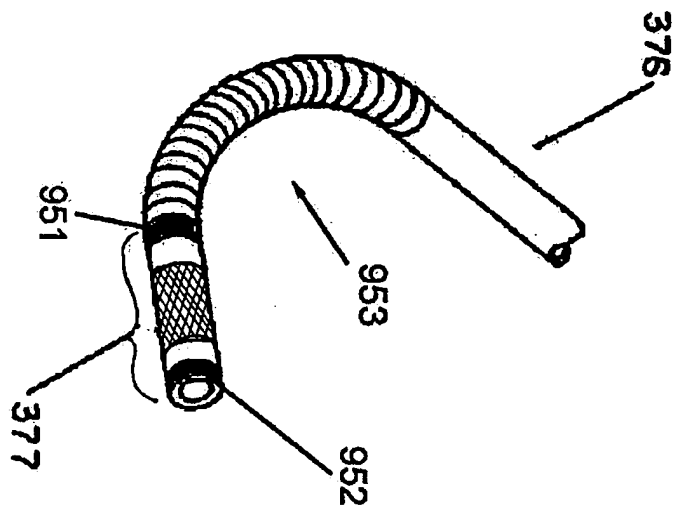


FIG. 6B

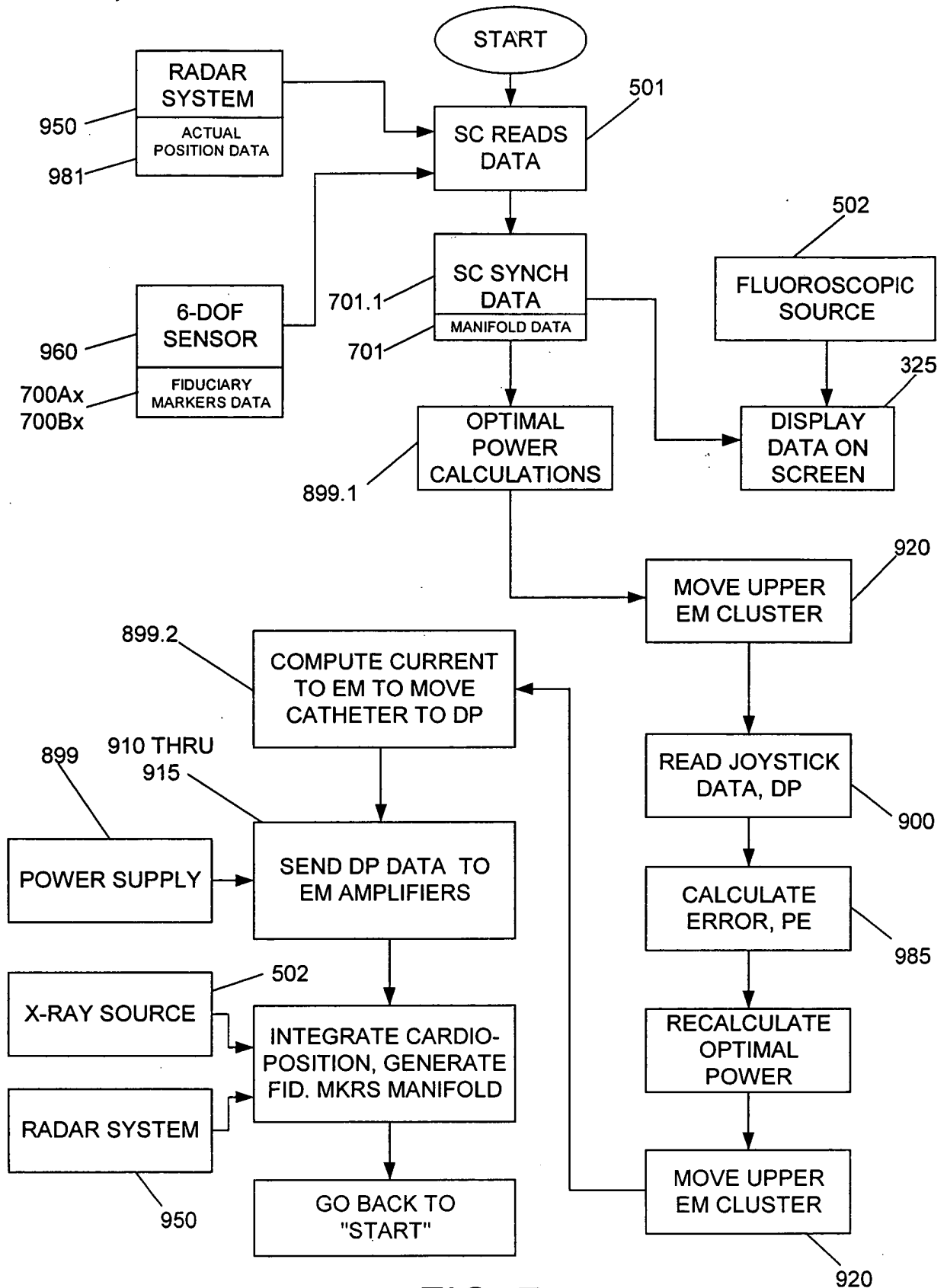


FIG. 7



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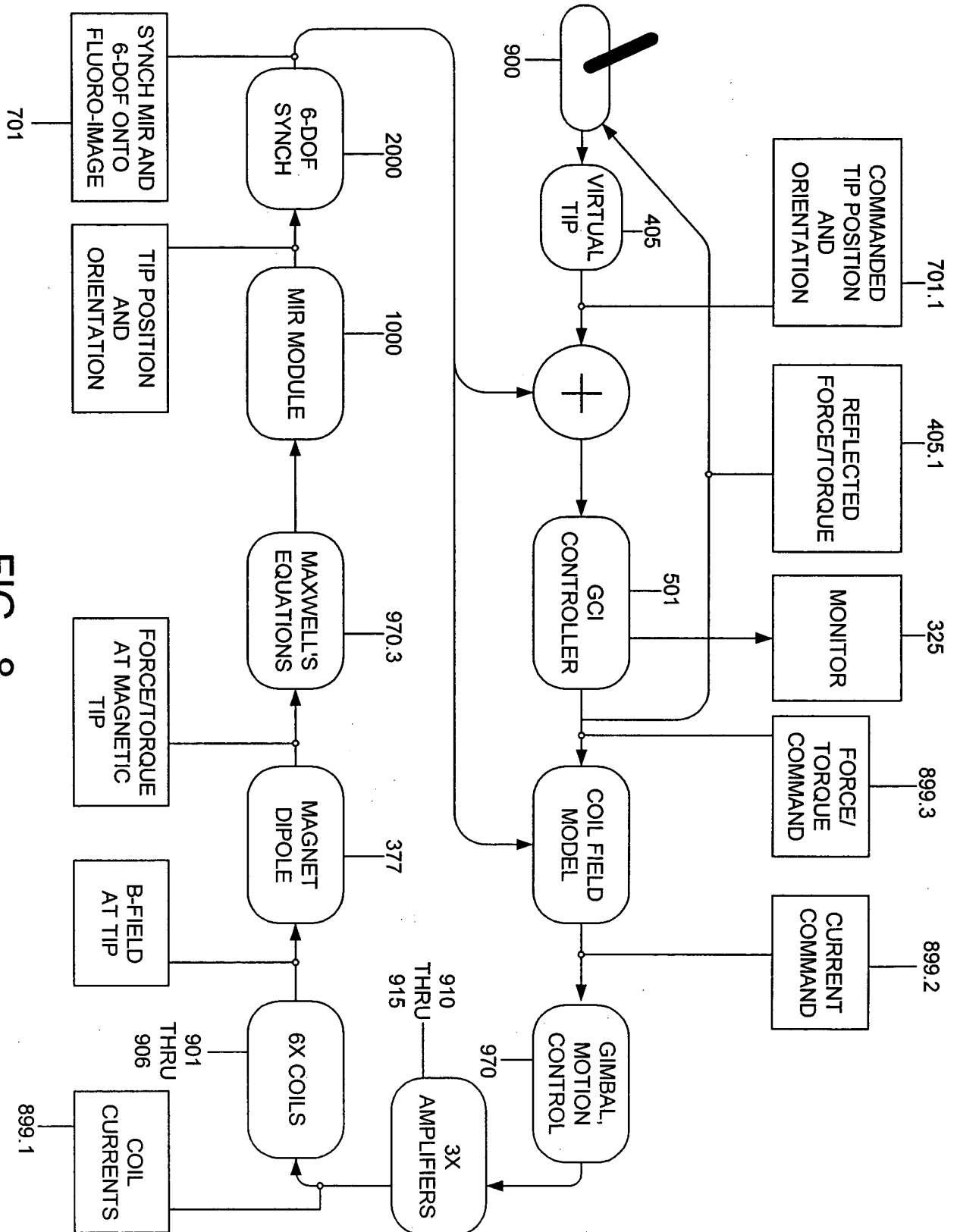
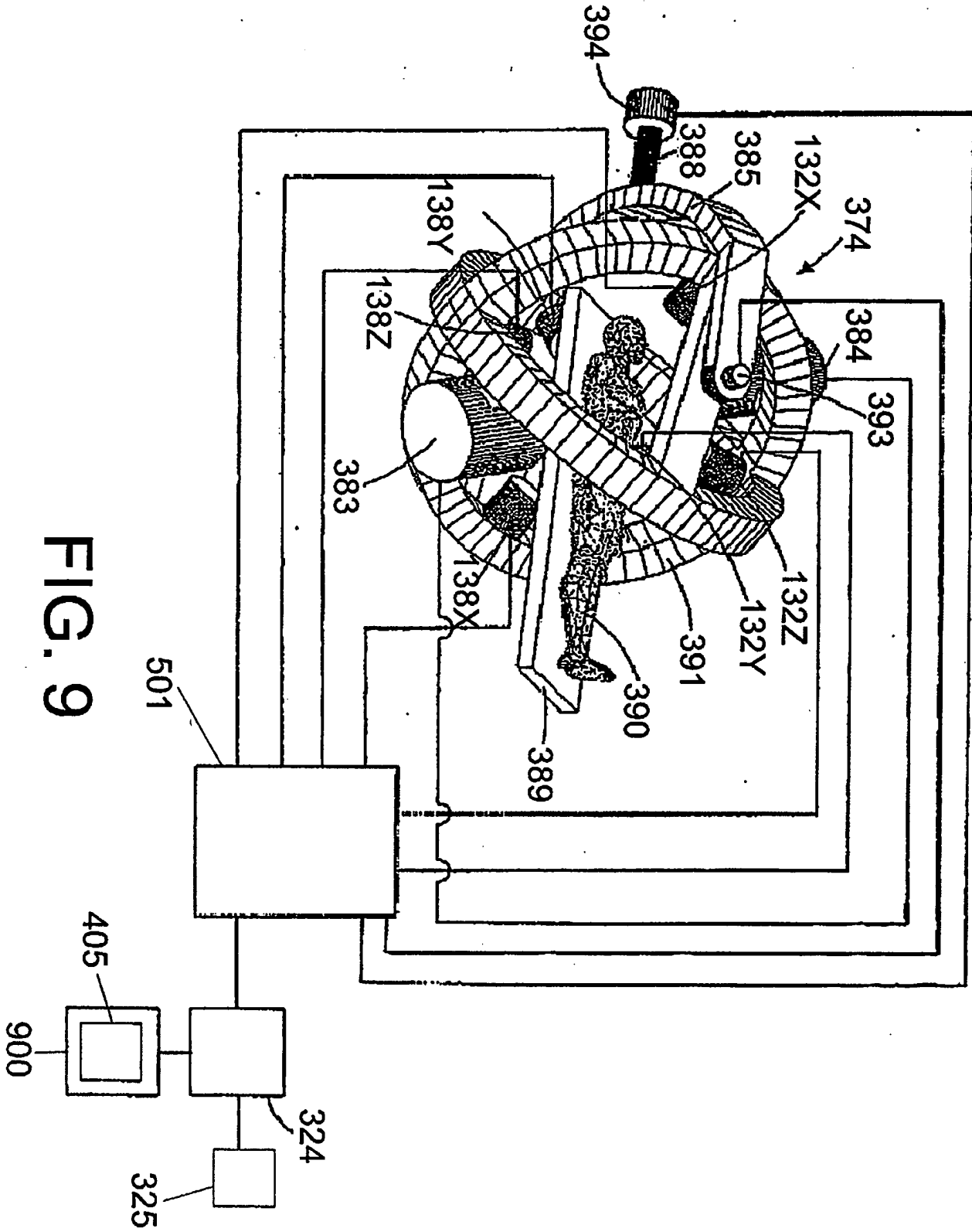


FIG. 8

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FIG. 11

